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teeth mesh model compression

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expended on the **compression of mesh models**. Although a **mesh model** usually consists of the ... cow, Agrippa, **teeth** and rabbit **models** defined by 5 804, 12 ...taylorandfrancis.metapress.com/index/X720848HK0832744.pdf - [Similar pages](#)**The Finite Element Method: a Tool to Study Orthodontic Tooth ...**Tension in the alveolar bone was far more predominant than **compression**. ... Generation of 3-D finite element **models** of restored human **teeth** using micro-CT ...jdr.iadrjournals.org/cgi/content/full/84/5/428 - [Similar pages](#)**Sponsored Links****Dental teeth model**Tooth model for dentist & education  
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Version 2 (Dec. 1999): ®. Body animation. ®. 3D **model compression** ... upper and lower teeth. touching. •Tongue: flat; tip touching front teeth ...

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$u, u) = p(r \cdot u) \geq 0$  and Hilbert Space.  $b(u, u) = a(u) > 0$ . ...  
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A cubic equation calculation apparatus calculates  $f(n)$  of a function when a cubic equation variable T=n is defined by  $f(T)=AT.sup.3 + BT.sup.2 + CT+D$  where A, ...  
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Coordinate point y; x2 (Number) point on the **curve** or control point to define ... x1 (Number) start point to define **curve**. Coordinate point x; y1 (Number) ...  
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We denote by  $(t, s)c$  the orbit **curve coordinate** system in AABC, where  $i(0 < t < 1)$  is the distance from a point  $x$  in the side AB to the point B (see Figure ...

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creating a **parametric representation** of a surface of the teeth from the digital ... knowledge of parameters associated with patient dental **data compression**. ...

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creating a **parametric representation** of the digital data set; ... possess in-depth knowledge of parameters associated with patient dental **data compression**. ...

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# Coordinate System Transformation

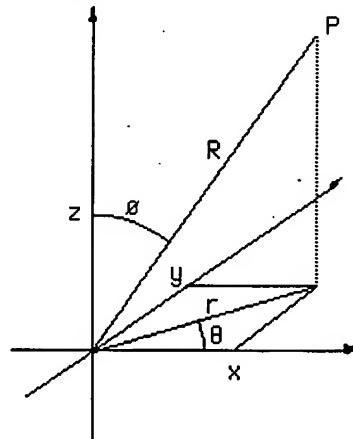
Written by Paul Bourke

June 1996

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There are three prevalent coordinate systems for describing geometry in 3 space, cartesian, cylindrical, and spherical (polar). They all provide a way of uniquely defining any point in 3D.

The following illustrates the three systems.



Equations for converting between cartesian and cylindrical coordinates

$$\begin{array}{lll} x = r \cos(\theta) & r = \sqrt{x^2 + y^2} & \sin(\theta) = y / \sqrt{x^2 + y^2} \\ y = r \sin(\theta) & \theta = \arctan(y/x) & \cos(\theta) = x / \sqrt{x^2 + y^2} \\ z = z & z = z & \end{array}$$

Equations for converting between cylindrical and spherical coordinates

$$\begin{array}{lll} r = R \sin(\theta) & R = \sqrt{r^2 + z^2} & \sin(\theta) = r / \sqrt{r^2 + z^2} \\ z = R \cos(\theta) & \theta = \arctan(r/z) & \cos(\theta) = z / \sqrt{r^2 + z^2} \\ \theta = \theta & \theta = \theta & \end{array}$$

Equations for converting between cartesian and spherical coordinates

$$\begin{array}{ll} x = R \sin(\theta) \cos(\phi) & R = \sqrt{x^2 + y^2 + z^2} \\ y = R \sin(\theta) \sin(\phi) & \theta = \arctan(y/x) \\ z = R \cos(\theta) & \phi = \arctan(\sqrt{x^2 + y^2} / z) \end{array}$$